

NASA CASE NO. GSC 13,360-1

PRINT FIG. 4

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(NASA-Case-GSC-13360-1) HIGH RELIABILITY
ROBOT FRIENDLY ORU INTERFACE Patent
Application (NASA) 25 p

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AWARDS DIGEST

HIGH RELIABILITY ROBOT FRIENDLY ORU INTERFACE

Shown in Figure 4 is a robot-friendly coupling device for an orbital replacement unit (ORU). The invention will provide a coupling that is detached and attached remotely by a robot. The design of the coupling must allow for slight misalignments, over torque protection, and precision placement. This is accomplished by means of a triangular interface comprising three components. A base plate assembly 2 is located on an attachment surface, such as a satellite. The base plate assembly 2 has a cup member 10, a slotted member 6, and a post member 8. The ORU that the robot attaches to the base plate assembly 2 has an ORU plate assembly 4 with two cone members 12 and a post member 8 which mate to the base plate assembly 2. As the two plates approach one another, one cone member 12 of the ORU plate assembly 4 only has to be placed accurately enough to fall into the cup member 10 of the base plate assembly 2. The cup member 10 forces alignment until a second cone member 12 falls into slotted member 6 which provides final alignment. A single bolt 24 is used to attach the two plates. Two deflecting plates 18 are attached to the backs of the plates. When pressure is applied to the center of deflecting plates 18, the force is distributed preventing the ORU & base plates from deflecting. This accounts for precision in the placement of the article.

Novelty is believed to reside in using deflecting plates in conjunction with kinematic mounts to provide distributed forces to the two plate members.

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Inventor: George M. Voellmer, Goddard Space Flight Center

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PATENT

NASA Case No. GSC 13,360-1

Application of: George Voellmer

TITLE OF THE INVENTION

HIGH-REPEATABILITY, ROBOT FRIENDLY, ORU INTERFACE

Origin of the Invention

The invention described herein was made by an employee of the United States Government, and may be manufactured and used by or for the Government for governmental purposes without the payment
5 of any royalties thereon or therefor.

Technical Field

This invention relates to coupling mechanisms and in
10 particular to coupling mechanisms specifically directed to attachment of Orbital Replacement Units.

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Background Art

The potential for servicing satellites in orbit in order to
lengthen their useful lives and to upgrade or change their function
5 has been of paramount importance to the United States space program
for some time. Equipment that provides for major spacecraft
functions can be housed in modules, commonly known as Orbital
Replacement Units (ORU's), that can be attached and detached, as
needed. The current trend is toward dependence on robotic rather
10 than astronaut activity and places exacting demands on the
mechanisms that interconnect the modules to the structures that
carry them. The attachment mechanisms must interface with the
robot's arm to insure alignment, provide a stable mount for
delicate instruments, and act as a path for the flow of
15 electricity, data and fluids, while maintaining simplicity or
operation.

Statement of the Invention

It is therefore an object of the present invention to provide
20 a highly repeatable, mechanical interface between an ORU and its

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base structure.

A further object of the invention is to provide an ORU coupling that has a high degree of repeatability and that does not require precise positioning of the interface to accomplish this,
5 making the device robot-friendly.

These and other objects are achieved by providing a robot-friendly coupling device for an Orbital Replacement Unit (ORU). The invention will provide a coupling that is detached and attached remotely by a robot. The design of the coupling must allow for
10 slight misalignments, over torque protection, and precision placement. This is accomplished by means of a triangular interface comprising three components. A base plate assembly is located on an attachment surface, such as a satellite. The base plate assembly has a cup member, a slotted member, and a post member.
15 The ORU that the robot attaches to the base plate assembly has an ORU plate assembly with two cone members and a post member which mate to the base plate assembly. As the two plates approach one another, one cone member of the ORU plate assembly only has to be placed accurately enough to fall into the cup member of the base
20 plate assembly. The cup forces alignment until a second cone falls

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into a slotted member which provides final alignment. A single bolt is used to attach the two plates. Two deflecting plates are attached to the backs of the plates. When pressure is applied to the center of the deflecting plates, the force is distributed preventing the ORU & base plates from deflecting. This accounts for precision in the placement of the article.

Brief Description of the Drawings

Figure 1 is a front view of a base plate assembly.

Figure 2 is a bottom view of the base plate assembly shown in figure 1.

Figure 3 is a top view of the base plate assembly shown in figure 1.

Figure 4 is a front view of the base plate assembly shown in figure 1 in close proximity to an ORU plate assembly.

Figure 5 is a perspective view of a slotted member used in the base plate assembly shown in figure 1.

Figure 6 is a perspective view of a cone member used in the ORU plate assembly shown in figure 4.

Figure 7 is a perspective view of a post member used in both the ORU plate assembly and base plate assembly.

Figure 8 is a perspective view of a cup member used in the base plate assembly shown in figure 1.

5 Figure 9 is a schematic of the coupling of the ORU plate assembly to the base plate assembly prior to preloading.

Figure 10 is a schematic of the coupling of the ORU plate assembly to the base plate assembly after preloading.

10 Detailed Description of the Invention

Referring now to FIG. 1, a front view of a base plate assembly 2 is shown. The high-repeatability, robot friendly, ORU interface will consist of this base plate assembly 2 and an ORU plate assembly, to be described later. The base plate assembly consists
15 of a base plate 14 which has affixed to it a slotted member 6, a post member 8, and a cup member 10 attached in a triangular configuration. This will be apparent later on. On top of base plate 14 is a deflecting plate 18, mounted above base plate 14 by three standoffs 20 and affixed to base plate 14 by three bolts 26
20 (only two of the three bolts are seen in this view). Base plate

14 is typically a rigid aluminum plate located on an attachment surface such as a satellite, and deflecting plate 18 is typically a thin spring plate capable of a moderate degree of deformation (e.g., a spring steel plate), to be explained later. Base plate assembly 2 also has a holddown bolt 24 affixed to deflecting plate 18 at its center position. In this embodiment, slotted member 6, post member 8, and cup member 10 are each attached to base plate 14 by bolts 22, however any suitable attachment method is possible.

Figure 2, which is a bottom view of base plate assembly 2 shown in figure 1, clearly shows the triangular mounting scheme of slotted member 6, post member 8, and cup member 10 on base plate 14. As shown, these members are affixed to base plate 14 by bolts 22, however, other attachment methods would be suitable. In addition to the bolts 22, the three members 6, 8, & 10 are also located by pins 28, but pins 28 may or may not be needed depending upon the method of attachment chosen for members 6, 8 and 10. Also shown in FIG. 2 is hole 25 in base plate 14 which allows holddown bolt 24 to pass through base plate 14; i.e., bolt 24 is not attached in any way to plate 14.

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Figure 3, which is a top view of base plate assembly 2 shown in figure 1, clearly shows the triangular shape of deflecting plate 18. Also shown are the three bolts 26 which affix deflecting plate 18 to standoffs 20 and ultimately to base plate 14; other methods of attachment are also suitable. Holddown bolt 24 is mounted in the center of deflecting plate 18 and permanently attached to deflecting plate 18 by any suitable method well known in the art.

Figures 5, 6, 7 and 8 detail the various members attached to the two plates. In FIG. 5, a perspective view is shown of slotted member 5, used on base plate assembly 2 shown in figure 1. In FIG. 6, a perspective view is shown of cone member 12, used in two places on ORU plate assembly 4 shown in figure 4. In FIG. 7, a perspective view is shown of post member 8, used on both base plate assembly 2 and ORU plate assembly 4. And in FIG. 8, a perspective view is shown of cup member 10, used on base plate assembly 2. These members are each made from a suitable material, such as anodized aluminum. Those skilled in the art will recognize these members as standard kinematic mount members, and the drawings are thus self explanatory in this regard.

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The triangular mounting of slotted member 6, post member 8, and cup member 10 on base plate 14 provides a standard kinematic mount, shown in FIG. 4, which is a front view of the base plate assembly 2 in close proximity to ORU plate assembly 4. This arrangement allows for high repeatability with a reasonable capture range. The method of preloading the resulting interface of ORU plate assembly 4 with base plate assembly 2 is critical, if very high repeatabilities are required. Bolting the two plate assemblies together through the middle would not be suitable as this would permanently deflect the two plates. Therefore, the two flexible, triangular deflecting plates 18 are incorporated into the design of the high-repeatability, robot friendly, ORU interface. The corners of deflecting plates 18 mount to standoffs 20 at the back ends of the kinematic mounts on both the ORU and base plates. Therefore, when a preload force is applied near the centers of these deflecting plates, they transmit a compressive force directly to the kinematic mount points, leaving the remaining portions of the mounting plates free from stresses and ensuing deflections. These deflecting plates can be deflected significantly without producing any stress or deflection in the two main plates.

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In order to achieve a precise preload with an imprecise torque on a screw fastener, the following system, shown schematically in figures 9 and 10, is used: The two plate assemblies 2 and 4 are brought into close proximity as shown in figures 4 and 9. Holddown bolt 24 now extends beyond deflecting plate 18 of ORU plate assembly 4. The kinematic alignment members are brought together and form a kinematic mount as described above. In this configuration, a stop collar 30 on holddown bolt 24 extends beyond ORU plate 16 but not as far as the lower deflecting plate 18. A nut 32 is threaded onto holddown bolt 24 and is tightened, which pulls the centers of the two deflecting plates 18 together, as shown in FIG. 10. Stop collar 30 limits the distance that the two deflecting plates 18 can be compressed. The driving torque has to be sufficient to ensure that stop collar 30 has been reached, but overtorque simply compresses nut 32 against stop collar 30, without increasing the preload on plates 14 and 16. When this is accomplished, a high-repeatability, robot friendly, ORU interface has been formed which will be repeatable to ± 40 millionths of an inch in the X, Y, and Z direction.

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An alternate method for compression of deflecting plates 18 would be to mount a floating nut to the center of deflecting plate 18 on base plate assembly 2. Since there is a hole in the center of base plate 14, ORU plate 16, and ORU deflecting plate 18, a bolt
5 could be passed through these holes to engage the floating nut on base plate deflecting plate 18. Engaging this bolt in the floating nut and tightening it would pull the centers of the two deflecting plates 18 together, as above, without contacting the main plates. A stop or shoulder on the bolt at a certain point would limit the
10 distance that the two deflecting plates could be compressed.

To those skilled in the art, many modifications and variations of the present invention are possible in light of the above teachings. It is therefore to be understood that the present invention can be practiced otherwise than as specifically described
15 herein and still will be within the spirit and scope of the appended claims.

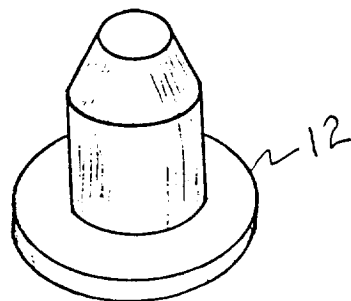
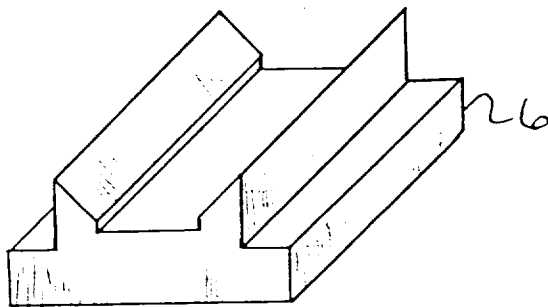
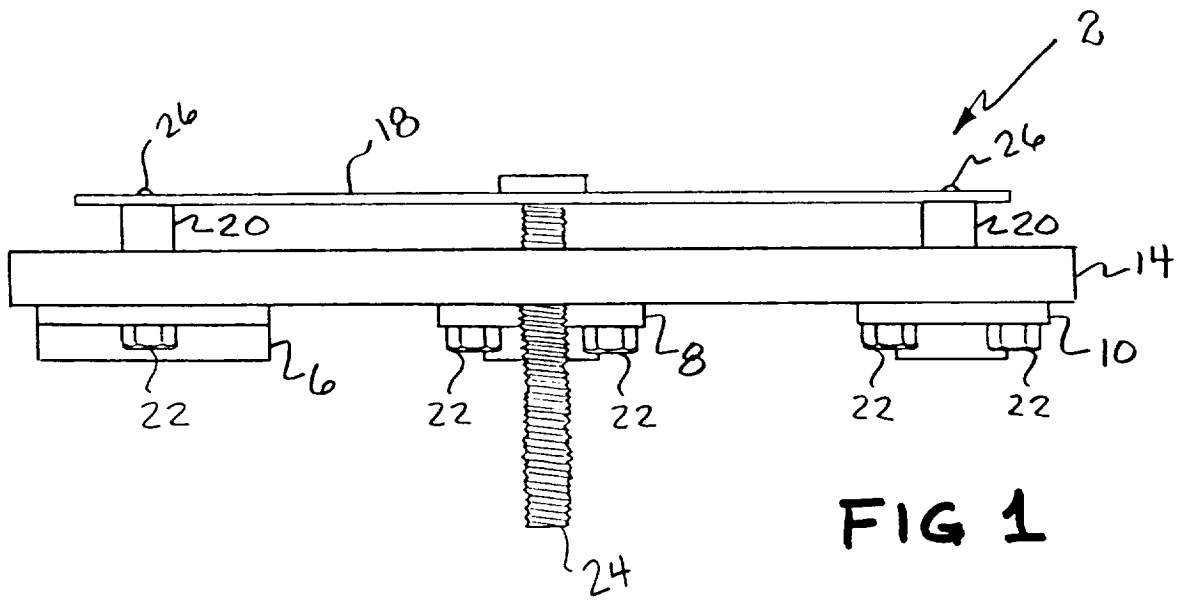
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ABSTRACT

A robot-friendly coupling device for an Orbital Replacement Unit (ORU). The invention will provide a coupling that is detached and attached remotely by a robot. The design of the coupling must
5 allow for slight misalignments, over torque protection, and precision placement. This is accomplished by means of a triangular interface having three components. A base plate assembly is located on an attachment surface, such as a satellite. The base plate assembly has a cup member, a slotted member, and a post member.
10 The ORU that the robot attaches to the base plate assembly has an ORU plate assembly with two cone members and a post member which mate to the base plate assembly. As the two plates approach one another, one cone member of the ORU plate assembly only has to be placed accurately enough to fall into the cup member of the base
15 plate assembly. The cup forces alignment until a second cone falls into a slotted member which provides final alignment. A single bolt is used to attach the two plates. Two deflecting plates are attached to the backs of the plates. When pressure is applied to the center of the deflecting plates, the force is distributed
20 preventing the ORU & base plates from deflecting. This accounts for precision in the placement of the article.

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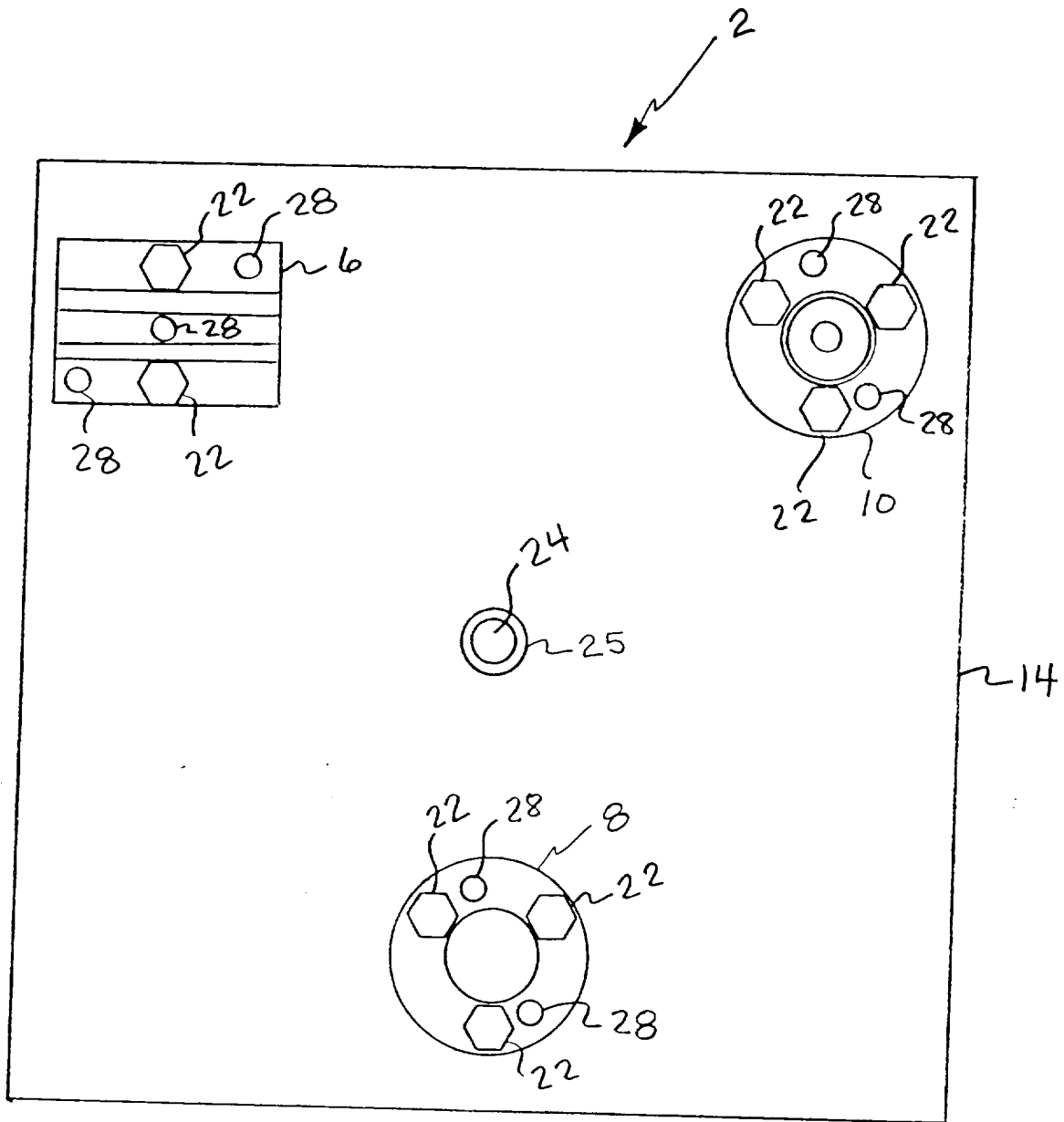


FIG 2

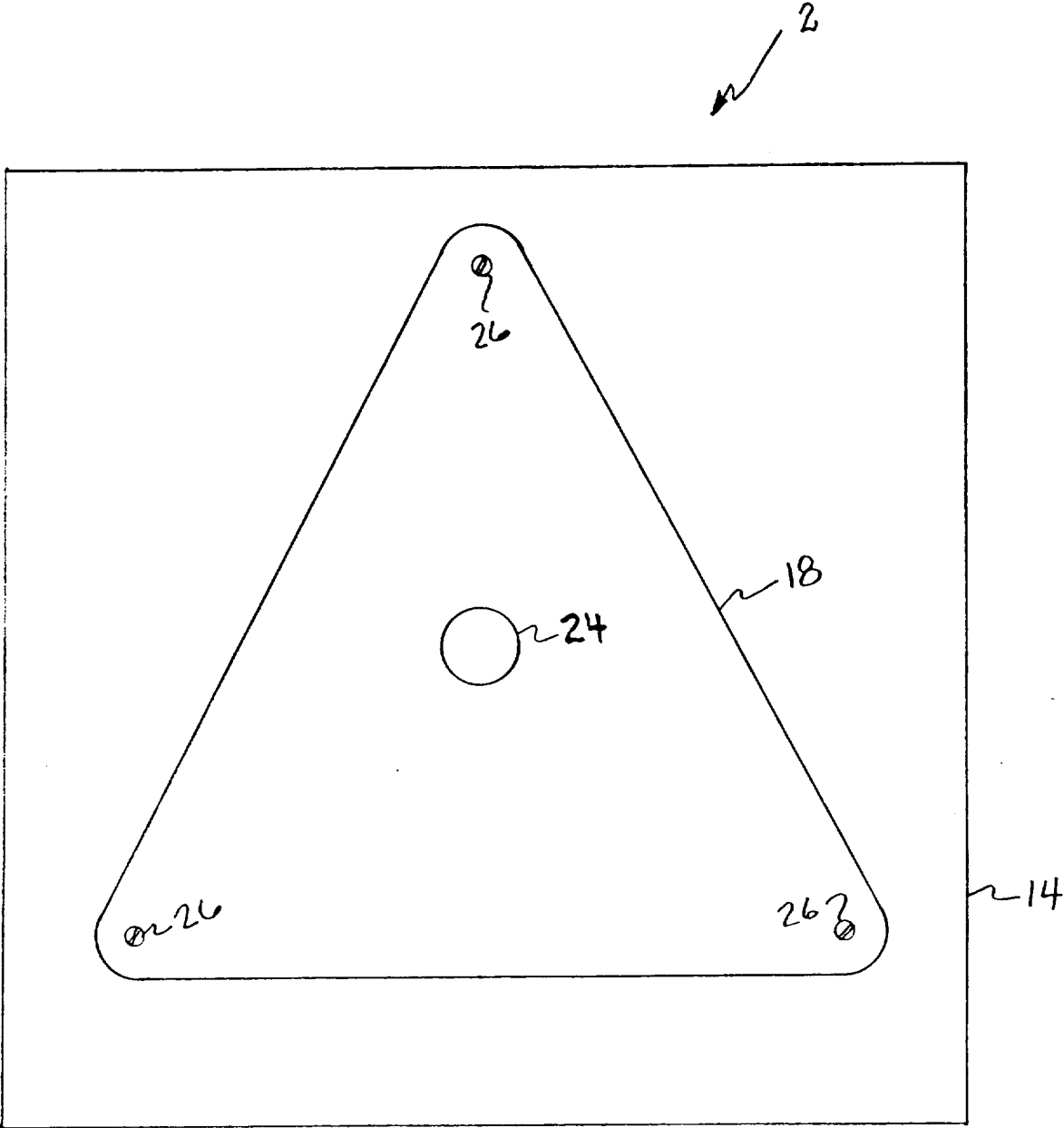


FIG 3

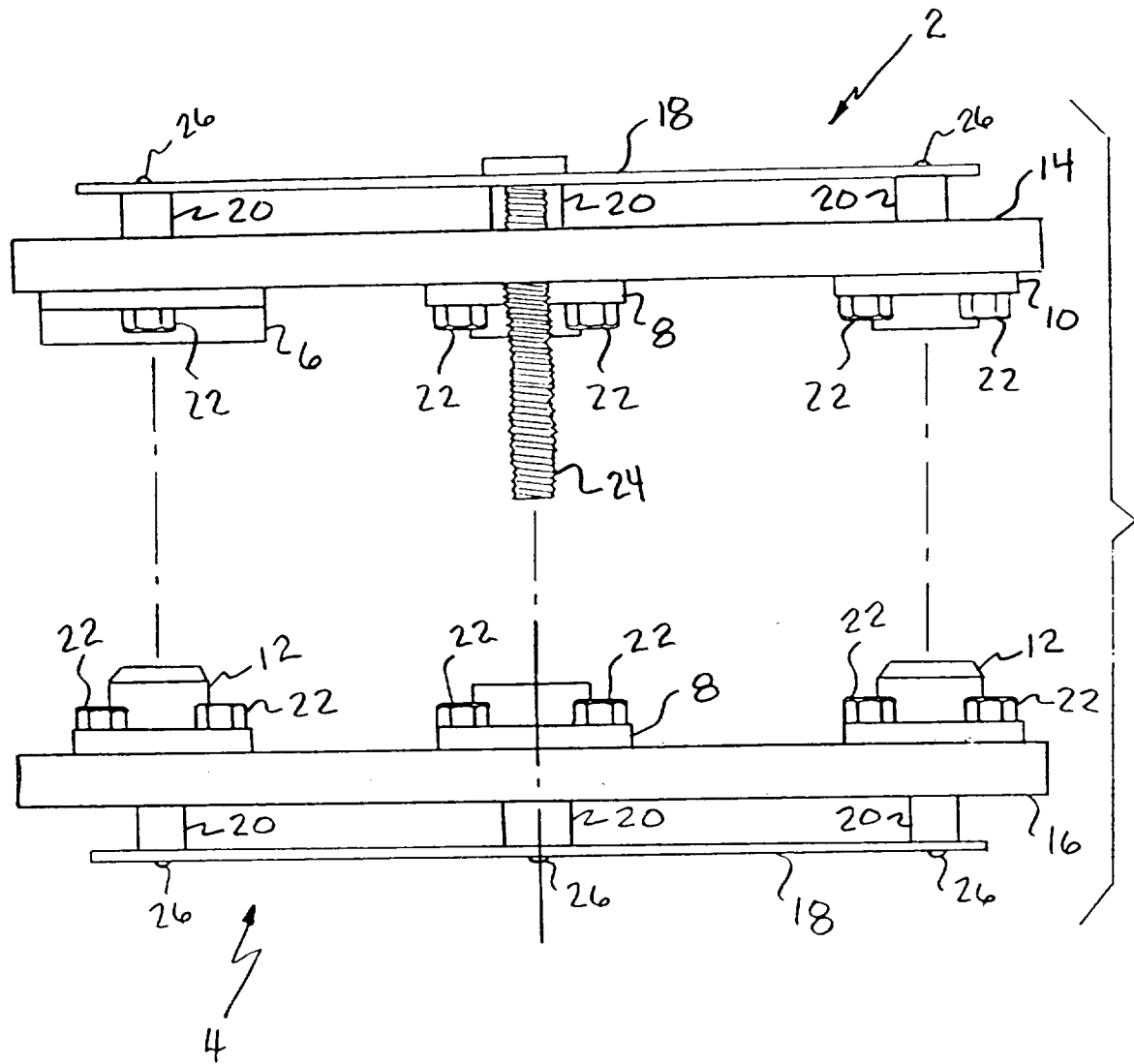


FIG 4

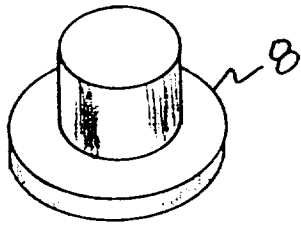


FIG 7

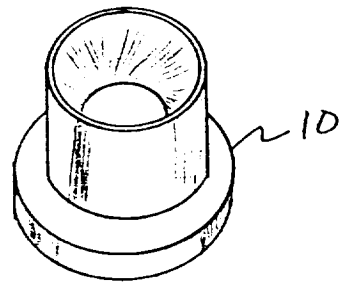
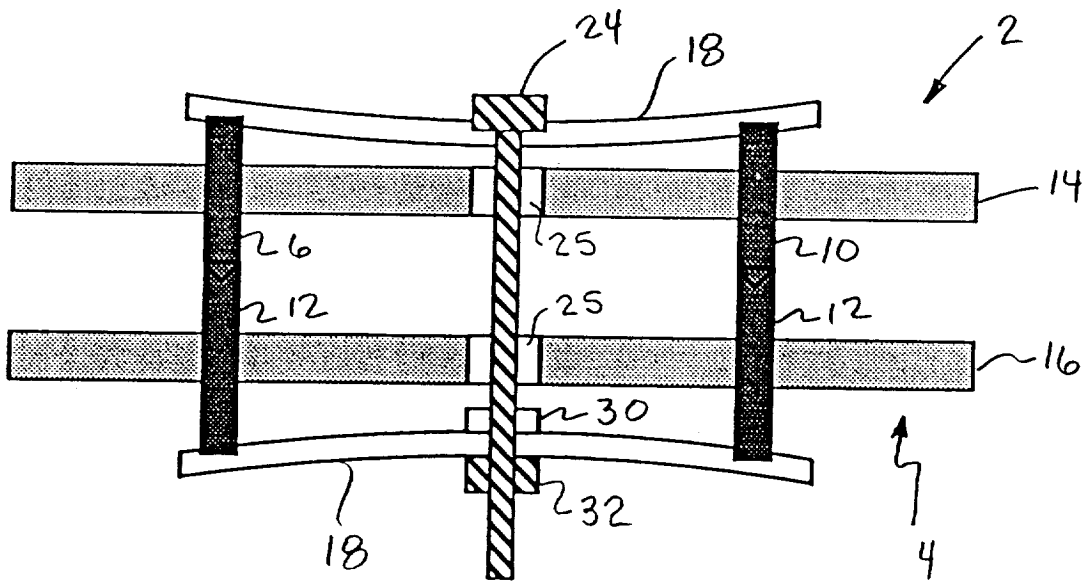
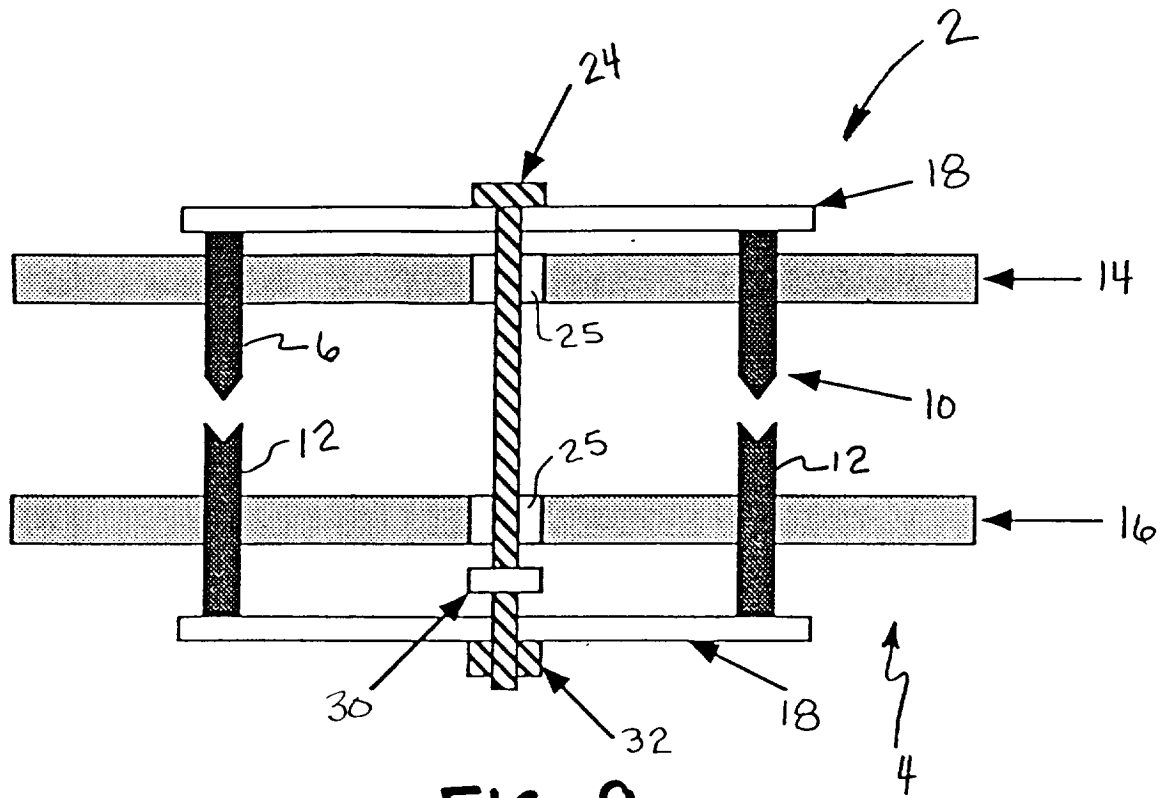


FIG 8



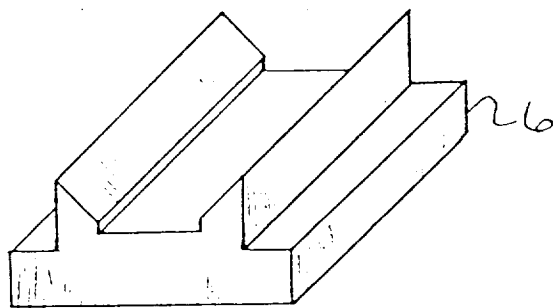
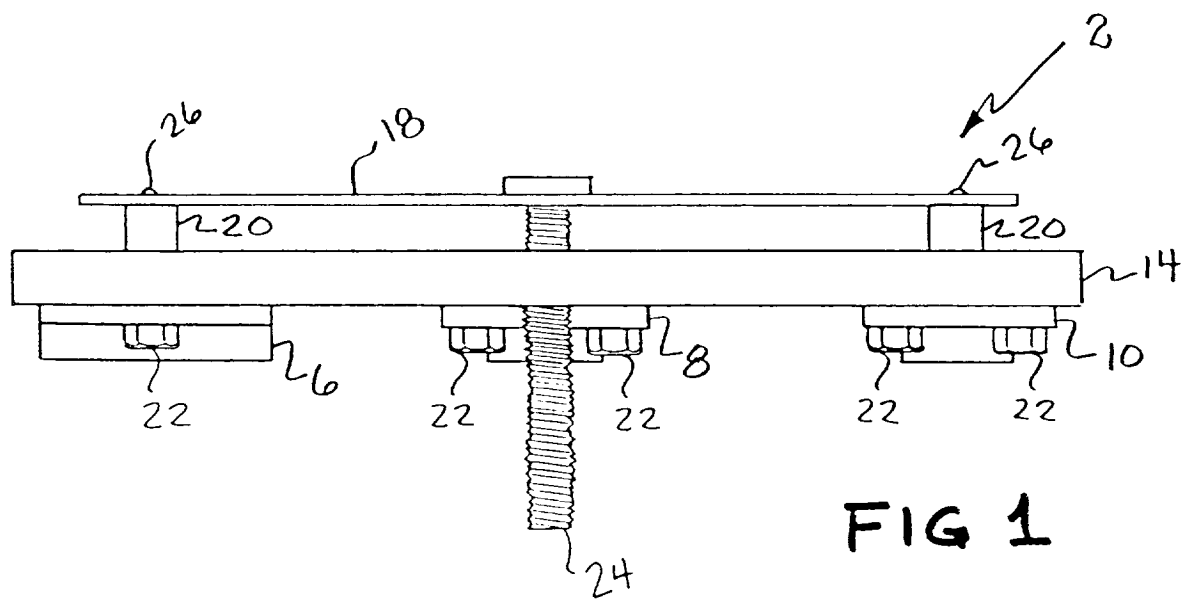


FIG 5

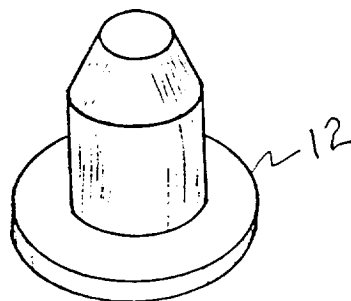


FIG 6

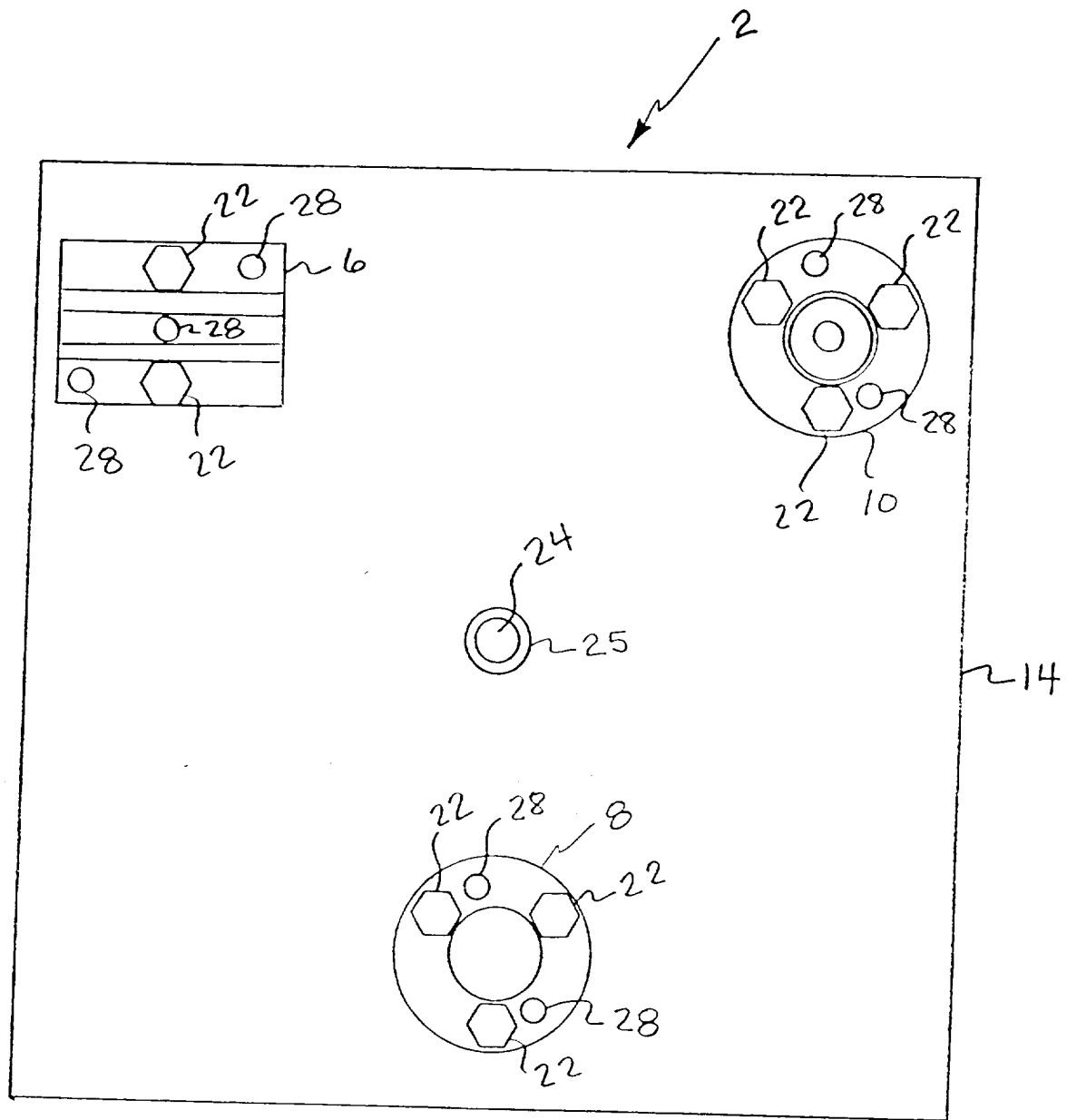


FIG 2

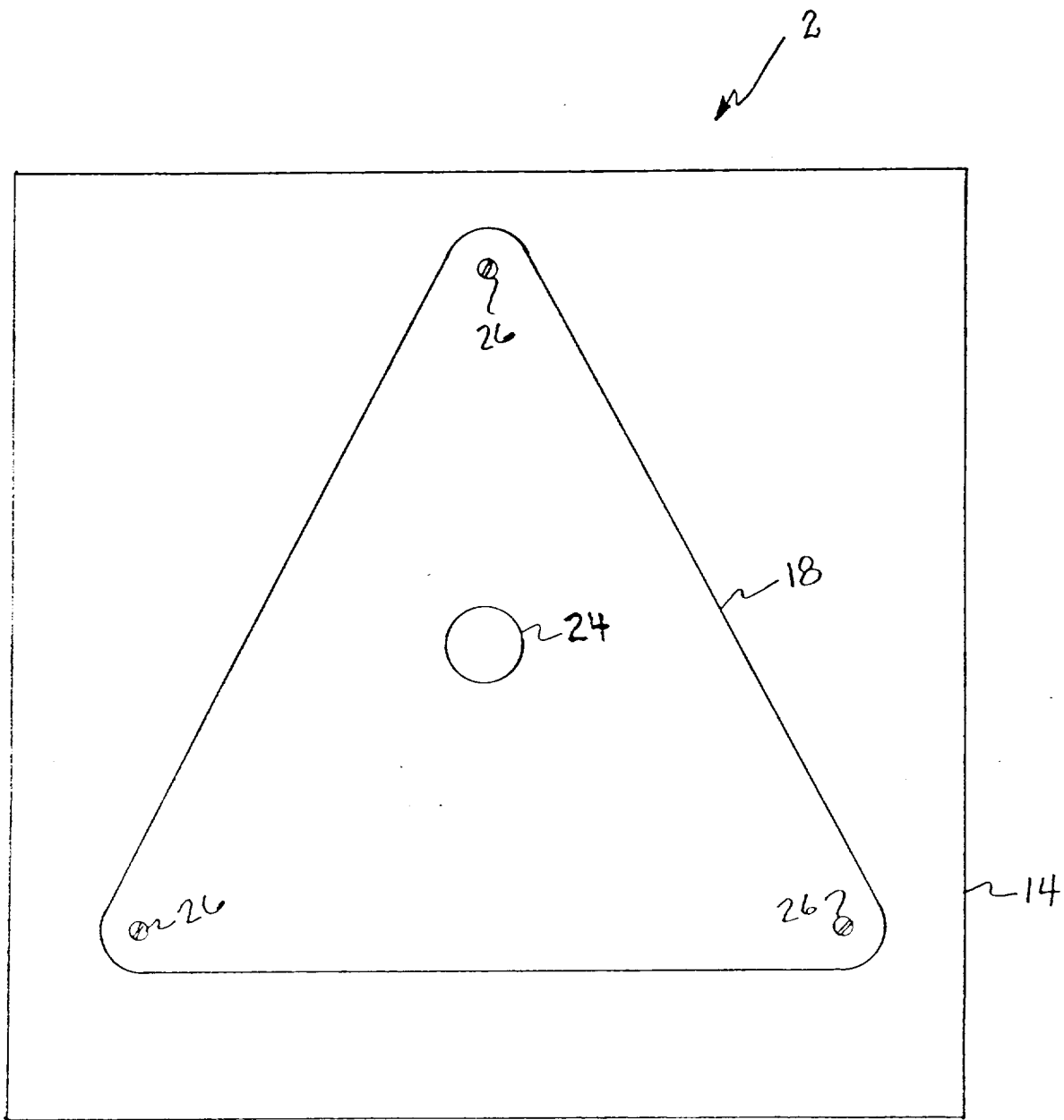
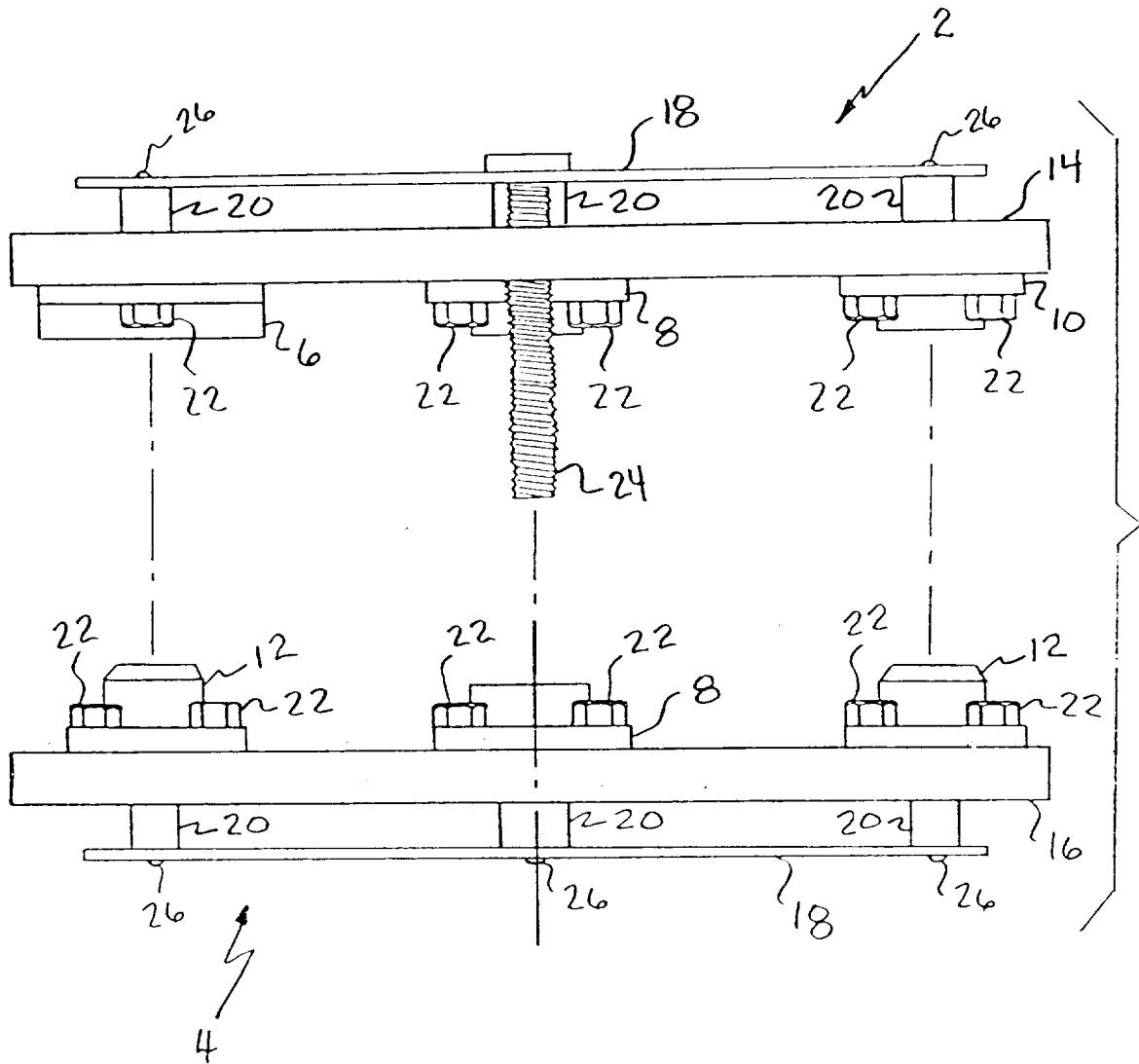


FIG 3



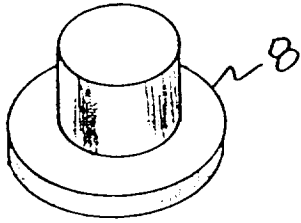


FIG 7

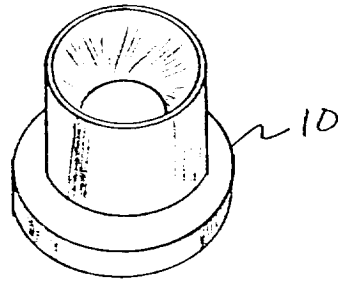


FIG 8

